

In the Claims:

Please amend the claims as follows:

1. (currently amended) ~~Method~~ A method for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, whereby the position of a target arranged on the first robot part is determined by the passage of a sensor arranged on the second robot part, said method comprising:

~~causing the target to include moving at least one of said first and second robot parts~~
~~relative to each other, said first robot part including the target having several distinct detectable~~
~~changes comprising step-like structural changes~~ height transitions, said ~~step-like structural~~
~~changes~~ height transitions being defined by sharp level differences in surfaces of said first robot
part and comprising walls or sides,

sensing at least two of said distinct detectable changes by the sensor at said respective
~~step-like structural changes~~ height transitions,

calculating the position of the target by ~~determining~~ calculating a center-point from
adjacent sensed height transitions ~~of adjacent step-like structural changes~~, and

introducing the calculated target position into the control system and comparing the target
position with a calibration position for the target in the control system.

2. (currently amended) ~~Method~~ The method according to claim 1, wherein calculating
the position of the target is effected by reading with the sensor which comprises a non-contact
sensor.

3. (currently amended) ~~Method~~ The method according to claim 1, wherein calculating the position of the target is effected by reading with the sensor which comprises a contact sensor.

4. (currently amended) ~~Method~~ The method according to claim 1, wherein the target comprises a groove with said ~~vertical~~ walls.

5. (currently amended) ~~Method~~ The method according to claim 1, wherein the target comprises an elevation with said ~~vertical~~ sides.

6. (currently amended) ~~Device~~ A device for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, the device comprising:

a target arranged on the first robot part; and

a sensor arranged on the second robot part,

wherein the target includes several distinct detectable changes comprising ~~step-like structural changes~~ height transitions, said ~~step-like structural changes~~ height transitions being defined by sharp level differences in surfaces of said first robot part and comprising ~~vertical~~ walls or sides, said sensor sensing at least two of said distinct detectable changes at said respective ~~step-like structural changes~~ height transitions to thereby enable the synchronizing of said robot by calculating a position of the target ~~corresponding to~~ by calculating a center-point of adjacent ~~step-like structural changes~~ height transitions.

7. (currently amended) ~~Device~~ The device according to claim 6, wherein the ~~step-like structural changes~~ height transitions comprise instantaneous level differences in the form of shoulder parts.

8. (currently amended) ~~Device~~ The device according to claim 6, wherein the target comprises a groove with said ~~vertical~~ walls.

9. (currently amended) ~~Device~~ The device according to claim 6, wherein the target comprises an elevation with said ~~vertical~~ sides.

10. (cancelled)

11. (currently amended) ~~Method~~ A method for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, whereby the position of a target arranged on the first robot part is determined by the passage of a sensor arranged on the second robot part, said method comprising:

~~causing the target to include~~ moving at least one of said first and second robot parts relative to each other, said first robot part including the target having height transitions comprising at least one of ~~substantially vertical~~ sides and ~~substantially vertical~~ walls, level differences in respective surfaces of said substantially vertical sides or walls defining distinct detectable structural changes in surfaces of said first robot part,

sensing at least two of said distinct detectable changes by the sensor at said respective structural changes,

calculating the position of the target by ~~determining~~ calculating a center-point from of adjacent sensed structural changes, and

introducing the calculated target position into the control system and comparing the target position with a calibration position for the target in the control system.

12. (currently amended) ~~Method~~ The method according to claim 11, wherein calculating the position of the target is effected by reading with the sensor which comprises a non-contact sensor.

13. (currently amended) ~~Method~~ The method according to claim 11, wherein calculating the position of the target is effected by reading with the sensor which comprises a contact sensor.

14. (currently amended) ~~Method~~ The method according to claim 11, wherein said target comprises a groove with said ~~substantially vertical~~ walls.

15. (currently amended) ~~Method~~ The method according to claim 11, wherein said target comprises an elevation with said ~~substantially vertical~~ sides.

16. (currently amended) ~~Device~~ A device for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, the device comprising:

a target arranged on the first robot part; and

a sensor arranged on the second robot part,

wherein the target includes height transitions comprising at least one of ~~substantially vertical~~ sides and ~~substantially vertical~~ walls, level differences in respective surfaces of said ~~substantially vertical~~ sides or walls defining distinct detectable structural changes in surfaces of said first robot part, said sensor sensing at least two of said distinct detectable changes at said respective structural changes to thereby enable the synchronizing of said robot by calculating a position of the target ~~corresponding to~~ by calculating a center-point of adjacent structural changes.

17. (currently amended) ~~Device~~ The device according to claim 16, wherein the structural changes comprise instantaneous level differences in the form of shoulder parts.

18. (currently amended) ~~Device~~ The device according to claim 19, wherein said target comprises a groove with said ~~substantially vertical~~ walls.

19. (currently amended) ~~Device~~ The device according to claim 19, wherein said target comprises an elevation with said ~~substantially vertical~~ sides.

20. (new) A method for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, a sensor on one of the first robot part and a target on another of the first robot part and the second robot part, said method comprising:

moving at least one of the first robot part and the second robot part such that the sensor passes the target, the target comprising a plurality of distinct detectable changes comprising walls or sides extending in a direction at a right angle to a direction of motion of the sensor;

sensing at least two of the distinct detectable changes with the sensor;

calculating a target position by calculating a center-point from adjacent sensed distinct detectable changes; and

introducing the calculated target position into the control system and comparing the target position with a calibration position for the target in the control system.

21. (new) A method for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, a sensor on one of the first robot part and a target on another of the first robot part and the second robot part, said method comprising:

moving at least one of the first robot part and the second robot part such that the sensor passes the target, the target comprising a plurality of spaced distinct detectable changes comprising walls or sides;

sensing at least two of the distinct detectable changes with the sensor;

calculating a target position by calculating a center-point from adjacent sensed distinct detectable changes; and

introducing the calculated target position into the control system and comparing the target position with a calibration position for the target in the control system.

22. (new) A device for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, the device comprising:

a target arranged on one of the first robot part and the second robot part, the target comprising a plurality of distinct detectable changes comprising walls or sides extending in a direction at a right angle to a direction of motion of the sensor; and

a sensor arranged another of the first robot part and the second robot part, the sensor being operative to sense at least two of the distinct detectable changes, thereby enable the synchronizing of said robot by calculating a position of the target by calculating a center-point of adjacent distinct detectable changes.